

EAST Search History

Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp
L1	294	(703/7).CCLS.	USPAT; USOCR	OR	OFF	2006/06/14 10:22
L2	225	I1 and simulat\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 10:22
L3	25	I2 and dynamic\$2 and kinematic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 10:23
L4	16	("5576727" "5625576" "5642469" "5754023" "5802353" "5880714" "5898599" "5987454" "6005551" "6046563" "6046727" "6075475" "6084587" "6111577" "6131097" "6283859").PN. OR ("7027965").URPN.	US-PGPUB; USPAT; USOCR	OR	ON	2006/06/14 10:51
L5	483	((700/25) or (700/28)).CCLS.	USPAT; USOCR	OR	OFF	2006/06/14 10:52
L6	151	I5 and simulat\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 10:52
L7	24	I6 and hybrid	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 10:52
L9	17	I7 and dynamic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:07
L10	997	((345/653) or (345/659) or (345/473)).CCLS.	USPAT; USOCR	OR	OFF	2006/06/14 11:07
L11	408	I10 and simulat\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:07
L12	37	I11 and dynamic\$2 and kinematic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:08
L13	4	I11 and dynamic\$2 and kinematic\$2 and hybrid	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:14
L14	137	(368/229).CCLS.	USPAT; USOCR	OR	OFF	2006/06/14 11:14

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L15	15	l14 and simulat\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:15
L16	10	l14 and dynamic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:15
L17	56	simulat\$5 same hybrid same three\$dimension\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:16
L18	16	simulat\$5 same hybrid same three\$dimension\$2 same dynamic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:17
L19	426	simulat\$5 same kinematic\$2 and dynamic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:18
L20	129	simulat\$5 same kinematic\$2 and dynamic\$2 and geometric\$3 and (animat\$3 or motion\$2)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:19
L22	64	simulat\$5 same kinematic\$2 and dynamic\$2 and geometric\$3 and (animat\$3 or motion\$2) and transition	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:19
L23	46	simulat\$5 same kinematic\$2 and dynamic\$2 and geometric\$3 and (animat\$3 or motion\$2) and transition and rotat\$3 and displac\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:25
L24	2297	hybrid same simulat\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:25
L25	40	hybrid same simulat\$5 and (dynamic and kinematic\$2)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:26

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L26	40	hybrid same simulat\$5 and (dynamic\$2 and kinematic\$2)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:26
L28	13	hybrid same simulat\$5 and (dynamic\$2 and kinematic\$2) and transition	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:28
L29	72	(dynamic\$2 and kinematic\$2) same simulat\$5 and transition	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:28
L30	40	(dynamic\$2 and kinematic\$2) same simulat\$5 and transition and table	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:28
L31	33	(dynamic\$2 and kinematic\$2) same simulat\$5 and transition and table and variable\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:28
L32	25	(dynamic\$2 and kinematic\$2) same simulat\$5 and transition and table and variable\$2 and rotat\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:29
L33	20	(dynamic\$2 and kinematic\$2) same simulat\$5 and transition and table and variable\$2 and rotat\$3 and displace\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:56
L34	12	simulat\$5 same hybrid same electromechanic\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 12:01
L35	7	test\$3 same debug\$4 same electro\$mechanic\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 12:02
L36	1	("5754023").PN.	USPAT; USOCR	OR	OFF	2006/06/14 12:25
S1	1	("5831853").PN.	USPAT; USOCR	OR	OFF	2006/06/14 10:22



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<u>#3</u>	(((simulation and hybrid and electromechanic)<in>metadata)) <and> (pyr >= 1950 <and> pyr <= 2003)		0
<u>#4</u>	(((debugging and testing and electromechanic)<in>metadata)) <and> (pyr >= 1950 <and> pyr <= 2003)		0
<u>#5</u>	(((hybrid and dynamic and kinematic)<in>metadata)) <and> (pyr >= 1950 <and> pyr <= 2003)		30
<u>#6</u>	(((hybrid and dynamic and kinematic)<in>metadata)) <and> (pyr >= 1950 <and> pyr <= 2003)		30
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<u>#11</u>	(((hybrid and dynamic and kinematic)<in>metadata)) <and> (pyr >= 1950 <and> pyr <= 2003)		30
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...Flight Research Center. **Simulation** benefits all phases...systems design and **testing**, and flight test support...envelope expansion. A **simulation** laboratory was established...support ground and flight **testing** of advanced research...relies extensively on **simulation** to support development...
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- ☐ **3. [Techniques for the Design and Simulation of Running Robots](#) [PDF-460K]**
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Techniques for the Design and **Simulation** of Running Robots by John Robert Ridgely...Berkeley 2001 Techniques for the Design and **Simulation** of Running Robots Copyright 2001 by...Abstract Techniques for the Design and **Simulation** of Running Robots by John Robert Ridgely...
[<http://www.calpoly.edu/~jridgely/research/jrrdiss.pdf>]
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...an algorithmic **debugging** framework for...Generalized Algorithmic **Debugging** and **Testing** method (GADT...valued and make the **simulation** models behave...associated to the **electromechanical** device **simulation** example is given...
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[Mechanical Tests](#)

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 ...automotive mechatronic systems, robotics, machine vision, experimental stress analysis, heat trans- fer, fluid flow, system **simulation**, circuits and communications, control, mechanical and electrical properties of materials, solid- state devices and microelectronics...
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 Laboratory experiments and lectures focus on a design and construction project, such as an autonomous moving vehicle. Prerequisites: Credit or registration in either Math 120 oe Calculus and Analytic Geometry, I., or Math 135 oe Calculus.
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 3 A Message from the Dean
 4 Henry Samueli School of Engineering and Applied Science
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- ❑ 10. [Simulation and construction of a speed control for a DC series motor](#)
Santana, J. / Naredo, J.L. / Sandoval, F. / Grout, I. / Argueta, O.J.,
Mechatronics, Nov 2002
 ...other developments. The **simulations** have permitted the **testing** and the **debugging** of the speed control...constructed. For instance, the **simulations** have helped to establish...costs substantially. The **simulations**, when combined with experimental...
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 ...executive and control mechanisms, and computer maintenance schemes:
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... Student Success Center · Placement **Testing** · Orientation 29 Fees and
Financial Aid...International Programs · 351.3127 CLEP **Testing** · 351.3594
Clubs and Organizations ·...Personnel, Staff · 351.3420 Placement **Testing** ·
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...from First Principles.....
48 2.3.6 Qualitative

Simulation

51 2.4 FAILURE CONTROL AND CORRECTION...

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the whole person . . . reaching out to every person's world with a message of
healing, wholeness, and abundant living Editors Dr. Debra Sowell, Dean of
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Jan 2000

Testing Embedded-Core Based System Chips Yervant Zorian
LogicVision...challenges. Section 3 presents a conceptual architecture for
testing such system chips, consisting of three structural elements...Test
Challenges In this section, the main challenges of **testing** system chips are
analyzed and compared to the traditional...

[http://www.ra.informatik.uni-stuttgart.de/~rainer/Lite...]

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❑ **16. TABLE OF CONTENTS** [PDF-58K]

Jan 2002

...EASY5. On-line interactive **debugging** tools are available between the user
and the **simulation** math models. Applications include laboratory design,
testing, and rapid prototyping of...prototype ECU to a real-time **simulation** of
the plant such that it...digital interface between the **simulation** computer and
ECU. Typical...

[http://0-ewh.ieee.org.csulib.ctstateu.edu/r4/se_michig...]

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❑ **17. Monitoring, testing and debugging of distributed real-time systems**

Thane, Henrik, Jan 2000

...Thane, Henrik Title: Monitoring, **testing** and **debugging** of distributed real-
time systems...real-time systems. Keywords Monitoring, **testing**, **debugging**,
testability, distributed real-time...natural reasons led me to also consider
testing, **debugging** and monitoring. That work gave fruit...

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...teamwork, written and oral communication skills, and uses computer tools (Electronic Workbench and MATLAB) for analysis and **simulation**. EGR 131 1 credit Introduction to Design .5 hours lecture, 1.5 hours laboratory For students not in the IMPULSE program, covers...

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..... 11 3.1.9.3

Testing.....

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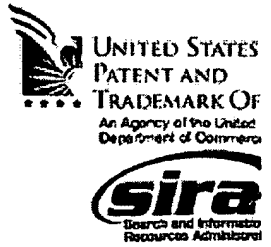
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1	INZZ	Kondo-K\$	unrestricted	1847	show titles
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Hybrid current-controlled VSI-IM drive

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Z Cucej, P Cafuta, R Sveclo - Advanced Motion Control, 2004 8th IEEE International ..., 2004 - [ieeexplore.ieee.org](#)

... responsible for the tracking of drive **kinematic** variables and ... Roughly, the **dynamics** of **HCC** are as follows, see ... assumed to start in a certain **hybrid** state, say ...

[Web Search](#)

Simulation of a Rover and Display in a Virtual Environment - group of 3 »

A Sweet, T Blackmon, V Gupta - Proc. of the American Nuclear Society 8th International ..., 1999 - [stratify.com](#)

... implementing a simple set of **kinematics** and **dynamics** ... including the rigid-body **dynamics**, power systems ... **Hybrid** CC and interval constraints." Proceedings of ...

Cited by 3 - [View as HTML](#) - [Web Search](#)

Use of hybrid models for testing and debugging control software for electromechanical systems

K Kondo, M Yoshida - Mechatronics, IEEE/ASME Transactions on, 2005 - [ieeexplore.ieee.org](#)

... with a three- dimensional **kinematics** simulator and a ... and A. Courtois, "Using **hybrid** concurrent constraint programming to model **dynamic** biological systems ...

[Web Search](#)

A local coordinate system for assumed strain shell element formulation - group of 2 »

HCC Park, SWC Lee - Computational Mechanics, 1995 - Springer

... Lee and Nan (1978) introduced the assumed strain **hybrid** formulation based on the ... excessively simple assumed strain field may trigger spurious **kinematic** modes. ...

Cited by 6 - [Web Search](#)

[PS] Model-enabled control of hybrid systems - group of 2 »

S McIlraith, G Biswas, M Fromherz, J Howe, R Fikes ... - 1998 - [ksl.stanford.edu](#)

... intents of neighboring aircraft, and **kinematic** models to ... modeling and analysis of **hybrid dynamic** physical systems ... by the declarative **hybrid** modeling, simulation ...

Cited by 3 - [View as HTML](#) - [Web Search](#)

Impedance control for articulated robot of 6 degree-of-freedom inconsideration of critically damped ... - group of 2 »

F Nagata, K Watanabe, K Sato, K Izumi, T Suehiro - SICE'97. Proceedings of the 36th SICE Annual Conference. ..., 1997 - [ieeexplore.ieee.org](#)

... Recently **Hybrid** ComplianceForce Control (**HCC**) methods4) were proposed ... Impedance Control From (I), the **dynamic** equation for a ... the same way as **HCC**, considering a ...

Cited by 7 - [Web Search](#) - [BL Direct](#)

[book] Simulating and Generating Motions of Human Figures - group of 2 »

K Yamane - 2004 - [books.google.com](#)

... A foundation for **dynamic** modeling of complex **kinematic** chains is established and original methods for interactive generation of human figure motions are ...

Cited by 3 - [Web Search](#) - [Library Search](#)

MBO (N) D: A multibody method for long-time molecular dynamics simulations - group of 2 »

HM Chun, CE Padilla, DN Chin, M Watanabe, VI ... - Journal of Computational Chemistry, 2000 - [doi.wiley.com](#)

... This results in the use of larger integration step sizes, substantially reducing the computational time required for a given **dynamic** simulation. ...

[Cited by 22](#) - [Web Search](#) - [BL Direct](#)

An Experiment on Force Control Using Fuzzy Environment Models

F Nagata, K Watanabe, K Sato, K Izumi, S Akama - *Procs. of the 4th International Symposium on ArtificialLife ...*, 1999 - [fmv5.fitc.pref.fukuoka.jp](#)

... Forward **Kinematics** ... *ASME Journal of Dynamic Systems, Measurement and Control*, vol. ...

K. Ioi, N. Kubota and O. Noro: Application of **Hybrid** Compliance/Force Control ...

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Investigating the Reaction Dynamics of Dicarbon Molecules, C

X Gu, Y Guo, AM Mebel, RI Kaiser - *Molecules* - [chem.hawaii.edu](#)

... These **dynamics** result in forward-scattered contour plots of the heavy ... C 3 H radical and about 25 % more abundant than the ethynyl radical (**HCC**; $X^2\Sigma^+$). ...

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hybrid and dynamic and kinematic a

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[Impedance control for articulated robot of 6 ...](#) - by Nagata - 7 citations

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simplified **kinematics** and **dynamics** for the rover, in order to test the software ... An **HCC** simulation is first created as a text file with the model to be ...

www-cs-students.stanford.edu/~vgupta/publications/rover-ans99.pdf - [Similar pages](#)

[Earthquake Physics: Seismicity and Source Process Posters ...](#)

The results from Model A and B are consistent with **kinematic** rupture model. ... Alaska

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